

**AMENDMENTS TO THE CLAIMS:**

This listing of claims will replace all prior versions and listings of claims in the application:

1. (Currently amended) An articulated robot comprising:

a plurality of joint arms connected to one another, wherein each of the joint arms is disposed coaxially, wherein each of the joint arms is connected to an adjacent joint arm via a rotating shaft, wherein the axis of a second rotating shaft at one end of one of the plurality of joint arms being is inclined relative to the axis of a first rotating shaft at the other end of the one of the plurality of the joint arms, and wherein each rotating shaft is provided with a motor for driving the rotating shaft and with a speed-reducing mechanism, and wherein the plurality of joint arms include a joint arm having two motors for driving the first and second rotating shafts and a joint arm with no motor, and wherein the joint arm with no motor is adjacently connected to the joint arm having two motors.

2. (Original) The articulated robot according to claim 1, wherein each of the first and second rotating shafts has a hollow part through which a cable or the like necessary for controlling the articulated robot is passed.

3. (Withdrawn) The articulated robot according to claim 1 or 2, wherein each joint arm is provided with a motor for driving either the first or the second rotating shaft connected thereto.

4. (Withdrawn) The articulated robot according to claim 1 or 2, wherein the plurality of joint arms comprises joint arms having the first rotating shaft on one end and the second rotating shaft on the other end, wherein, among the joint arms with the first and second rotating shafts, joint arms having two motors for driving the first and second rotating shafts and joint arms with no motor are alternately connected.

5. (Withdrawn) The articulated robot according to claim 1, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

6. (Withdrawn) The articulated robot according to claim 2, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

7. (Withdrawn) The articulated robot according to claim 3, wherein at least one joint arm is provided with a brake device independent of the motor, the brake device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.

8. (Withdrawn) The articulated robot according to claim 4, wherein at least one joint arm is provided with a brake device independent of the motor, the brake

device being disposed in parallel with the motor relative to gears constituting a speed reducing mechanism.